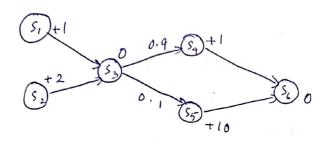
CS5500

Reinforcement Learning (RL) Assignment No. 2

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by n



a)
$$V(S_6) = 0$$

 $V(S_4) = +1+0 = 1$
 $V(S_5) = 10+0 = 10$
 $V(S_3) = 0.9 \times 1 + 0.1 \times 10 + 0 = 0.9 + 01 = 1.9$
 $V(S_2) = 2 + V(S_3) = 2 + 1.9 = 3.9$
 $V(S_1) = 1 + V(S_3) = 1 + 1.9 = 2.9$

for (b), (c), (d) 4 (e), the trajectories along with the rewards are written as follows -

$$(1) \quad S_1(1) \xrightarrow{\rho} \quad S_2(0) \longrightarrow S_4(1) \longrightarrow S_6(0)$$

(2)
$$S_1(1) \rightarrow S_3(0) \rightarrow S_5(10) \rightarrow S_6(10)$$

$$(3) \quad \varsigma_1(1) \rightarrow \quad \varsigma_3(0) \rightarrow \quad \varsigma_4(1) \rightarrow \quad \varsigma_6(0)$$

$$(9) \quad \varsigma_{1}(1) \rightarrow \varsigma_{3}(0) \rightarrow \varsigma_{4}(1) \rightarrow \varsigma_{6}(0)$$

$$(5) \quad \varsigma_{1}(2) \rightarrow \varsigma_{3}(0) \rightarrow \varsigma_{5}(0) \rightarrow \varsigma_{1}(0)$$

b)
$$V(s_1) = \frac{1}{4} (2 + 11 + 2 + 2) = \frac{17}{4} = 4.25$$

 $V(s_2) = \xrightarrow{24} \frac{12}{1} = 12$

2) Id us initially
$$V(s_1) = V(s_2) = V(s_1) = V(s_n) = V(s_n) = 0$$
 $K_{\epsilon} = \frac{1}{4}$

After first species,

 $V(s_1) = 0$
 $V(s_2) = 0 \rightarrow \frac{1}{4}(10 + 0 - 0) = 1$
 $V(s_3) = 0 + \frac{1}{4}(1 + 0 - 0) = 1$
 $V(s_3) = 0 + \frac{1}{4}(1 + 0 - 0) = 1$
 $V(s_1) = 0$
 $V(s_2) = 0 \rightarrow \frac{1}{4}(10 + 0 - 0) = 1$
 $V(s_3) = 0 + \frac{1}{4}(1 + 0 - 0) = 1$
 $V(s_1) = 0 \rightarrow \frac{1}{4}(1 + 0 - 1) = 1$
 $V(s_1) = 0 \rightarrow \frac{1}{4}(1 + 0 - 1) = 1$
 $V(s_1) = 0$
 $V(s_1) = 1 \rightarrow \frac{1}{4}(1 + 0 - 1) = 1$
 $V(s_1) = 3 \rightarrow \frac{1}{3}(1 + \frac{1}{3} - 3) = 3 - \frac{5}{4} = \frac{5}{4}$

After finish spisods,

 $V(s_1) = 3 \rightarrow \frac{1}{3}(1 + \frac{1}{3} - 3) = 3 - \frac{5}{4} = \frac{5}{4}$

After finish spisods,

 $V(s_1) = 0$
 $V(s_2) = 5 \rightarrow \frac{1}{7}(10 + 0 - 5) = 6$
 $V(s_3) = \frac{1}{2} + \frac{1}{5}(0 + 6 - \frac{1}{2}) = \frac{8}{5}$
 $V(s_1) = 0 \rightarrow \frac{1}{5}(2 + \frac{8}{5} - 0) = \frac{18}{25}$
 $V(s_2) = 0 \rightarrow 2$

d) From In given samples,

 $P(s' = s_4 \mid s = s_3) = \frac{2}{5} = 0 \rightarrow 6$
 $V(s_3) = \frac{2}{3} \approx 1 + \frac{2}{5} \approx 10 = \frac{23}{5}$
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 $V(s_3) = \frac{2}{3} \approx 1 + \frac{2}{5} \approx 10 = \frac{23}{5} \approx 10 \rightarrow 6$
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The estimate of V(s2) by TD(0) method is the closest to
to true rester. MC estimate is for from the true rester.

This is because > there is botherping in TD but not in MC

The number of spriodes is very few for MC

to work efficiently

$$d_{t} = \frac{1}{t^{2}} \text{ will not nearly in convergence}$$

$$(3) \quad d_{t} = \frac{1}{t^{2}} \cdot 2 \cdot 1 \quad \Rightarrow \infty$$

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$$d_{t} = \frac{1}{t^{2}} \cdot 3 \quad \Rightarrow \infty$$

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$$d_{t} = \frac{1}{t^{2$$

integral tut.

$$\begin{vmatrix}
\frac{1}{t}e^{t}dt &= \lim_{D\to\infty} \frac{x^{1-p}}{1-p} |_{-p}^{D} = \lim_{D\to\infty} \frac{D^{1-p}}{1-p} - \frac{1}{1-p}$$
The converges when $1-p \ge 0 < 0$

$$\begin{vmatrix}
\frac{1}{t}e^{t}dt &= \lim_{D\to\infty} \frac{x^{1-p}}{1-p} |_{-p}^{D} = \lim_{D\to\infty} \frac{D^{1-p}}{1-p} - \frac{1}{1-p}$$

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$$\begin{vmatrix}
\frac{1}{t}e^{t}dt &= \lim_{D\to\infty} \frac{x^{1-p}}{1-p} |_{-p}^{D} =$$

$$=$$
 \times $< \frac{-0.693}{ln(\lambda)}$

$$n(\lambda) = -\frac{0.693}{ln(\lambda)}$$

both on streets writing a program for the given HDP and nurming it, we get the pellowing policy on convergence—

g s = s, a = a₃
s = s₂, a = a₃
s = s₃, a = a₃

The D- beautiff the given trajectory is (s, a, 1, s, a₂, 2, s₂)

This is periody because the agent follows & gendy approach.

Both the actions in this trajectory are kan dom.